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AMENDMENTS TO THE SPECIFICATION

Please replace the paragraph at page 1, lines 10-15 with the following rewritten paragraph:

The present invention relates to estimating **the** precise position of a stationary or moving object using multiple satellite signals and a network of multiple receivers. The present invention is particularly suited to position estimation in real-time kinetic environments where it is desirable to take into account the spatial distribution of the ionosphere delay.

Please replace the paragraph at page 1, lines 17-28 with the following rewritten paragraph:

Satellite navigation systems, such as GPS (USA) and GLONASS (Russia), are intended for ~~accuracy~~ **accurate** self-positioning of different users possessing special navigation receivers. A navigation receiver receives and processes radio signals broadcast by satellites located within line-of-sight distance, and from this, computes the position of the receiver within a ~~pre-defined~~ **predefined** coordinate system. However, for military reasons, the most accurate parts of these satellite signals are encrypted with codes only known to military users. Civilian users cannot access the most accurate parts of the satellite signals, which makes it difficult for civilian users to achieve accurate results. In addition, there are sources of noise and error that degrade the accuracy of the satellite signals, and consequently reduce the accuracy of computed values of position. Such sources include carrier ambiguities, receiver time offsets, and atmospheric effects on the satellite signals.

Please replace the paragraph at page 2, lines 10-27 with the following rewritten paragraph:

In a first aspect of the present invention, an exemplary apparatus/method comprises receiving the known locations of a first base station and a second base station, obtaining a time offset representative of the time difference between the clocks of the first and second base stations, and obtaining measured satellite data as received by the rover, the first base station, and the second base station. The measured satellite data comprises pseudo-range information. The exemplary apparatus/method generates a first set of residuals of differential navigation equations associated with a set of measured pseudo-ranges related to a first baseline (R–B1) between the rover and the first base station. The residuals are related to the measured satellite data received